

IN THE CLAIMS:

1. (Currently Amended) A machining device for ~~said~~ components (2), ~~especially body parts, with, the device comprising:~~ a multiaxial transport means; ~~a (6) and at least one said tool (11), characterized in that~~ at least one said carrier ~~[(7)]~~ with ~~one or more said~~ a multiaxial machining unit units (8, 9) with a plurality of said tools (11) ~~are arranged at the~~ a transport means ~~[(6)]~~.

2. (Currently Amended) A machining device in accordance with claim 1, **characterized in that** wherein the transport means ~~[(6)]~~ is designed as a multiaxial transport robot.

3. (Currently Amended) A machining device in accordance with claim 1 ~~or 2~~, **characterized in that** wherein the machining units (8, 9) are designed as ~~said~~ multiaxial small robots ~~[(10)]~~ each with one of said tools.

4. (Currently Amended) A machining device in accordance with claims 1, ~~2 or 3~~, **characterized in that** wherein the machining units (8, 9) are arranged on different sides of the carrier ~~[(7)]~~.

5. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, **characterized in that** wherein the machining units (8, 9) can be controlled individually.

6. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, ~~characterized in that~~ wherein the machining units (8, 9) can be controlled from the transport means ~~[[6]]~~.

7. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, ~~characterized in that~~ wherein the carrier ~~[[7]]~~ is designed as an essentially straight girder.

8. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, ~~characterized in that~~ wherein the small robots ~~[[10]]~~ are designed as six-axis articulated arm robots.

9. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, ~~characterized in that~~ wherein the machining units (8, 9) are arranged on different sides of the carrier ~~[[7]]~~, offset in relation to one another.

10. (Currently Amended) A machining device in accordance with ~~one of the above claims~~ claim 1, ~~characterized in that~~ wherein the machining units (8, 9) carry said replaceable tools ~~[[11]]~~.

11. (Currently Amended) A machining device in accordance with ~~one of the above~~

~~characterized in that the~~ wherein each machining device ~~(s) (5)~~ is~~[(/are)]~~ designed as a portal robot/portal robots.

16. (Currently Amended) A method of machining ~~said~~ cubic components ~~[(2)]~~, especially ~~said body parts~~, by means of a multiaxial transport means ~~[(6)]~~ and at least one ~~said~~ tool ~~[(11)]~~, ~~characterized in that~~ and further comprising the steps of: employing the transport means ~~(6) introduces~~ for introducing at least one ~~said~~ carrier ~~[(7)]~~ with one or more ~~said~~ multiaxial machining units ~~[(11)]~~ into the interior space of the component ~~[(2)]~~, wherein the machining units ~~(8, 9)~~ carry out machining operations on the inside of the component ~~[(2)]~~.

17. (Currently Amended) A method in accordance with claim 16, ~~characterized in that~~ wherein the component ~~[(2)]~~ is clamped on the inside by one or more said machining units ~~(8, 9)~~ and is machined by said other machining units ~~(8, 9)~~.

18. (Currently Amended) A method in accordance with claim 16 ~~or 17~~, ~~characterized in that~~ wherein the carrier ~~[(7)]~~ with the machining units ~~(8, 9)~~ is introduced through an opening into the component ~~[(2)]~~.

19. (Currently Amended) A method in accordance with claims 16, ~~17 or 18~~, ~~characterized in that~~ wherein the carrier ~~[(7)]~~ with the machining units ~~(8, 9)~~ is additionally

supported in the working position by a support means [(22)].